

AMENDMENTS TO THE SPECIFICATION

Please replace the second full paragraph on page 3 with the following new paragraph:

In order to solve the above problems, a carrier robot system according to Claim 1 is characterized, in a carrier robot system comprising a robot which has a placement portion for placing an object presenting a low-profile form thereon and carries the object and a robot controller for controlling the robot, in that a jig positioned in a predetermined direction and mounted on the placement portion of the robot and having an image pickup member; an image processing portion for processing an image picked up by the image pickup member; and a superior control portion for controlling the robot controller and image processing portion from a superior position are provided.

Please replace the first full paragraph on page 4 with the following new paragraph:

A control method for a carrier robot according to Claim 2 is characterized, in a control method for a carrier robot for carrying an object presenting a low-profile shape placed at a predetermined placement position, in that a jig having an image pickup member is positioned in a predetermined direction and placed in advance on a placement portion of a front end of an arm of the robot, the robot is shifted to a position where the image pickup member can detect a characteristic part existing in the vicinity of the predetermined placement position, an image including the characteristic part is picked up by the image pickup member, a position of the characteristic part in a coordinate system of the image pickup member is determined based on the picked-up image, and a position on the coordinate system of the image pickup member is transformed into a position on a coordinate system of the robot to determine the placement position.